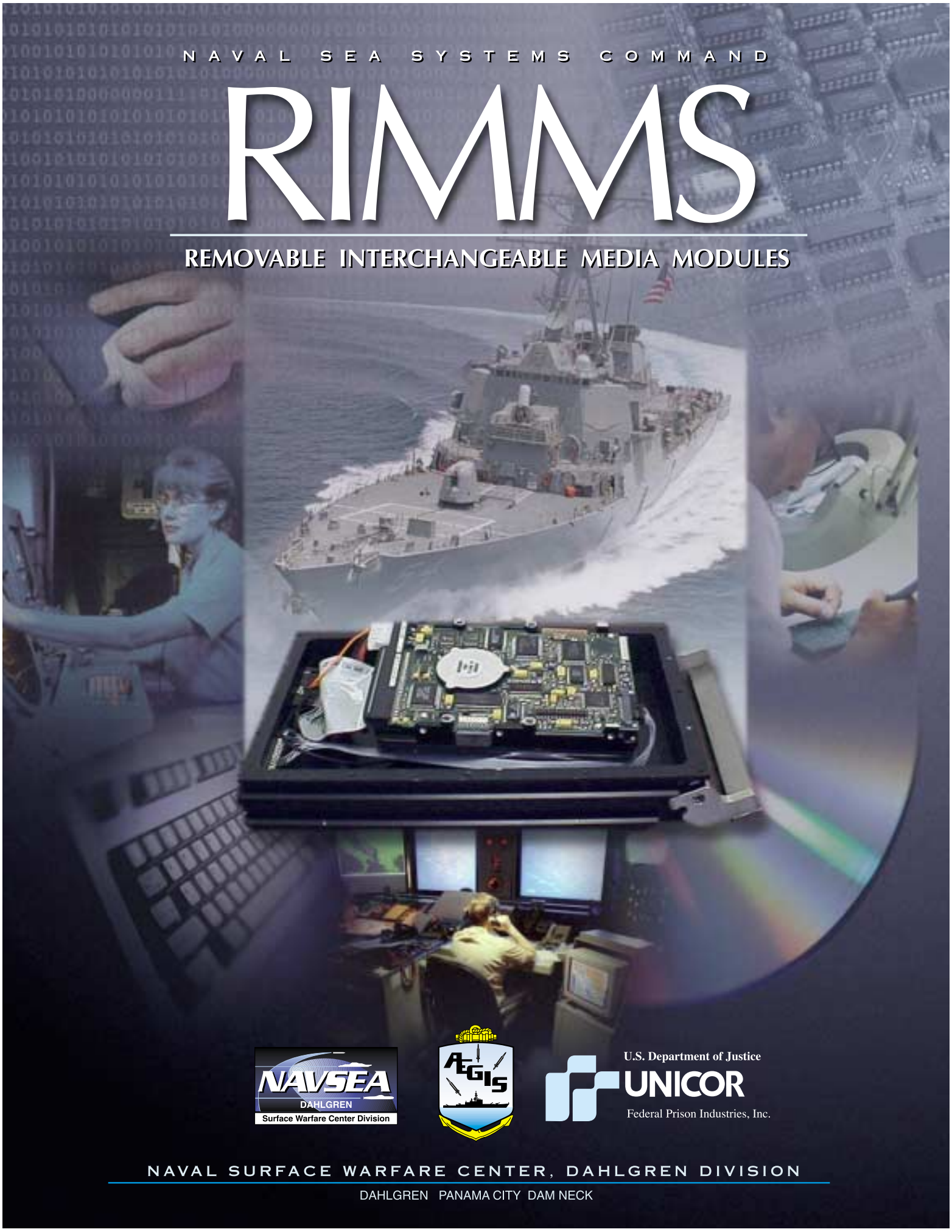
NAVAL SEA SYSTEMS COMMAND

RIMMS

REMOVABLE INTERCHANGEABLE MEDIA MODULES



NAVSEA DAHLGREN Surface Warfare Center Division

AEGIS

U.S. Department of Justice
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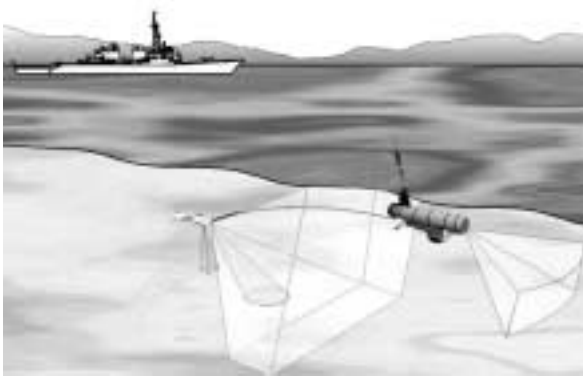
NAVAL SURFACE WARFARE CENTER, DAHLGREN DIVISION

DAHLGREN PANAMA CITY DAM NECK

Description

The AN/WLD-1(V) 1 Remote Minehunting System (RMS) is an off-board system that is organic to the Battle Group. It has been designed to meet Fleet demand for beyond line-of-sight mine reconnaissance against bottom and moored mines in deep and shallow water regions of anticipated operating areas. The remotely operated system will detect, classify, and identify mines and record their precise location for avoidance and/or removal. The system has been designed to be integral to forces deployed anywhere in the world, providing a mine countermeasures capability to surface combatant forces in the absence of dedicated mine countermeasure forces.

The RMS program has exercised a series of developmental prototypes in a Fleet environment to a final, fully supported operational system. Completed in August, 1994, the RMS (V)1 combined and integrated a semi-submersible vehicle, the AN/AQS-14 minehunting sonar (on a variable depth winch), and the SeaBat forward-looking sonar. The RMS(V)1 variant was launched pier side and operated from USS John Young (DD973) during the Kernel Blitz 95. Completed in December 1996, the RMS(V)2 added a DD963 class compatible launch and recovery system and an interface to the ship's AN/SQQ-89 Undersea Warfare Combat System. The RMS(V)2 variant was installed and deployed on the USS Cushing (DD985) with the Kitty Hawk Battle Group to the Persian Gulf and participated in SHAREM 119. The next variant, RMS(V)3 included a new vehicle, developed to meet full operations requirements, and will be exercised in a Fleet environment. The final RMS variant, AN/WLD1(V) will be the system introduced to and operated by the Fleet and will be capable of beyond line-of-sight operations. It will reflect lessons learned from the early variant, fully meet the system's Operational Requirements, and include an Electro-Optic sensor to positively identify mines detected by the system's sonars.



The AN/WLD-1(V)1 will be installed on DDG91 and then on the following later ARLEIGH BURKE Class hulls. It will be fully integrated into the ship's AN/SQQ-89(V)1 Undersea Warfare Combat System and include a launch and recovery system integral to the ship. Other surface ships that are being considered as host platforms for AN/WLD-1(V)1 are LPD17 (AUSTIN Class) amphibious assault ships and the 21st Century Surface Combatant. The planned AN/WLD1(V)1 acquisition strategy summary, which evolves to meet near and far-term requirements, is listed below:

- *RMS(V)1 Operational Prototype (RMOP)(FY95)*
  - Modified DOLPHIN Semi-submersible
  - AN/ASQ-14 and Reson SeaBat Sonars
  - Mission Command & Display Center (MILVAN)
- *RMS(V)2 (FY97)*
  - (V)1 System plus a DD963 Class Launch & Recovery System
  - Installed on USS Cushing (DD985)
  - KITTY HAWK Deployment
  - Participated in exercise SHAREM 119
- *RMS(V)3 (FY99)*
  - New Vehicle (Focus on Operational Requirements)
- *AN/WLD-1(V)1 (MSIII-FY05)*
  - RMS(V)3 System with an AN/AQS-20 Mine Hunting Sonar sensor suite
  - Electro-Optic Mine Identification Sensor
  - Full Capability
  - Integration into the AN/AQS-89(V)15 Ship's Undersea Warfare Combat System

Program Status

The combined Milestone acquisition decision was approved in May 1996. Lockheed Martin is currently under contract to produce the AN/WLD-1(V)1 with the first delivery expected in FY04.

NAVSEA
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Coastal Systems Station

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